

APPARATUS AND METHOD FOR CATHETER GUIDANCE CONTROL...

Yehoshua Shachar

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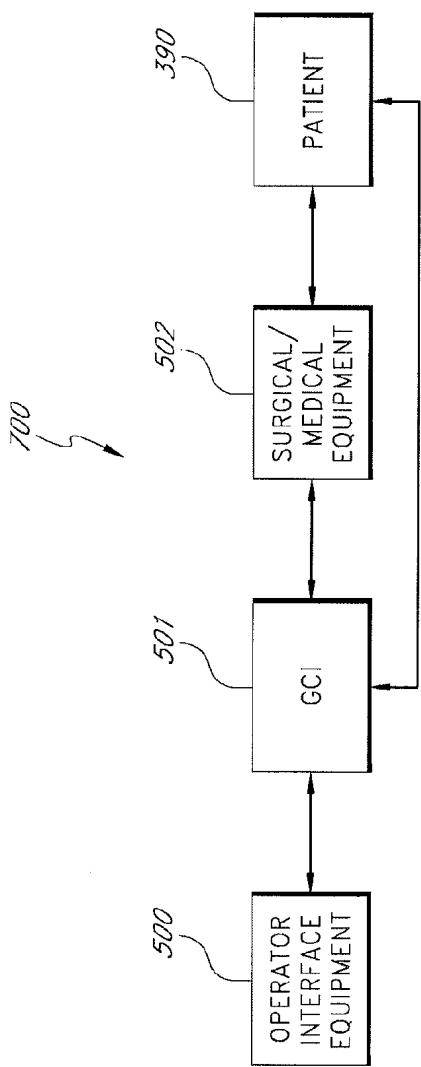


FIG. 1A

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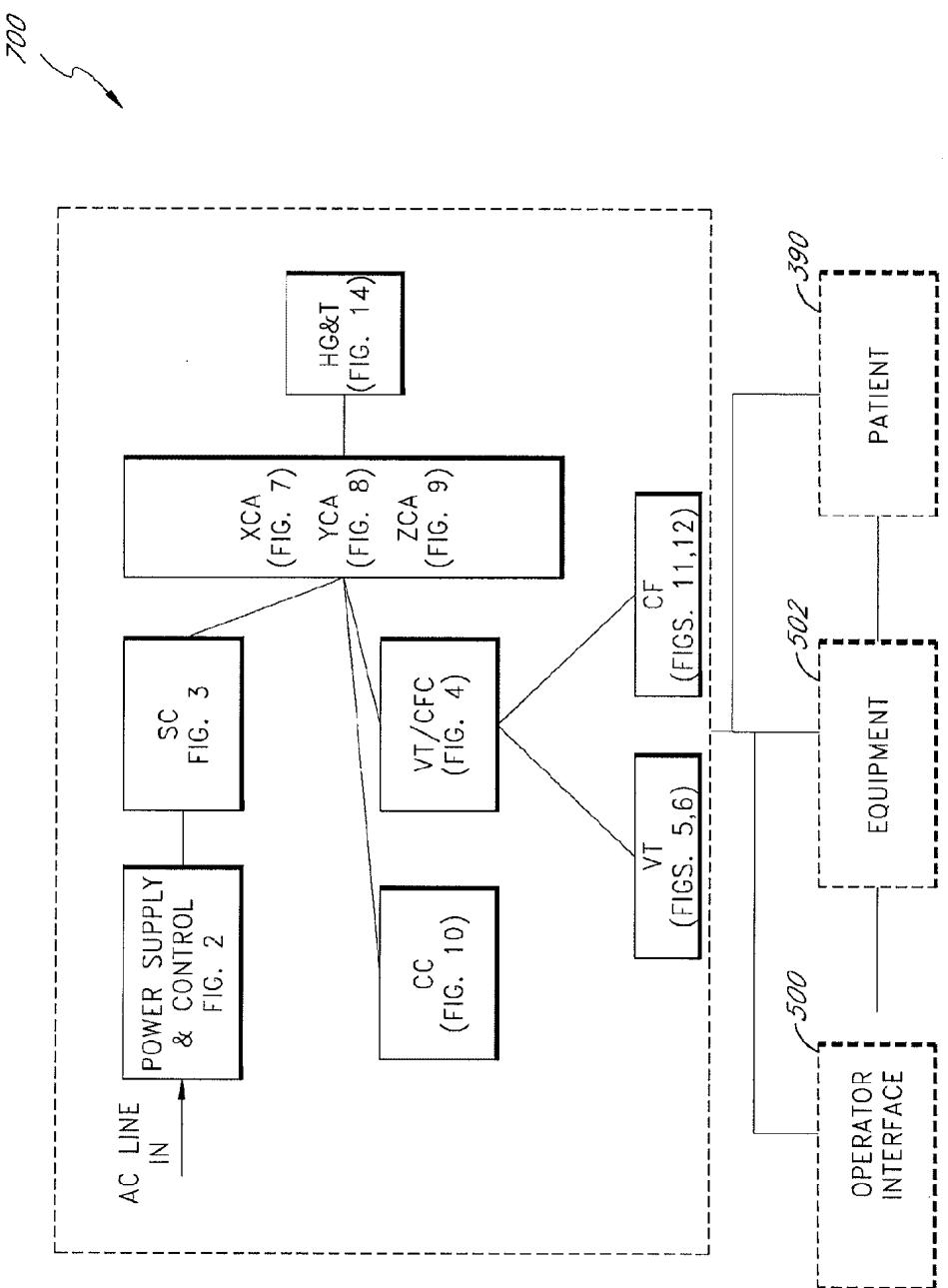


FIG. 1B

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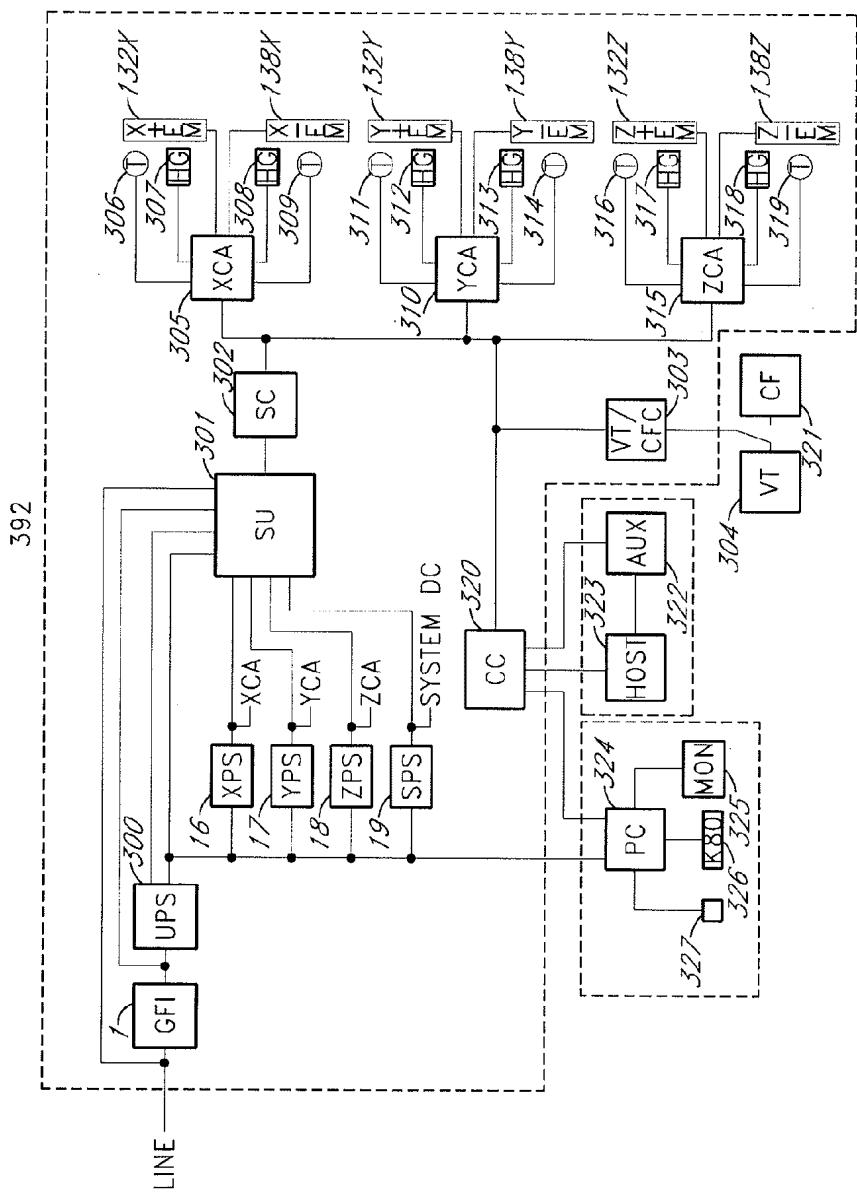


FIG. 1C

700

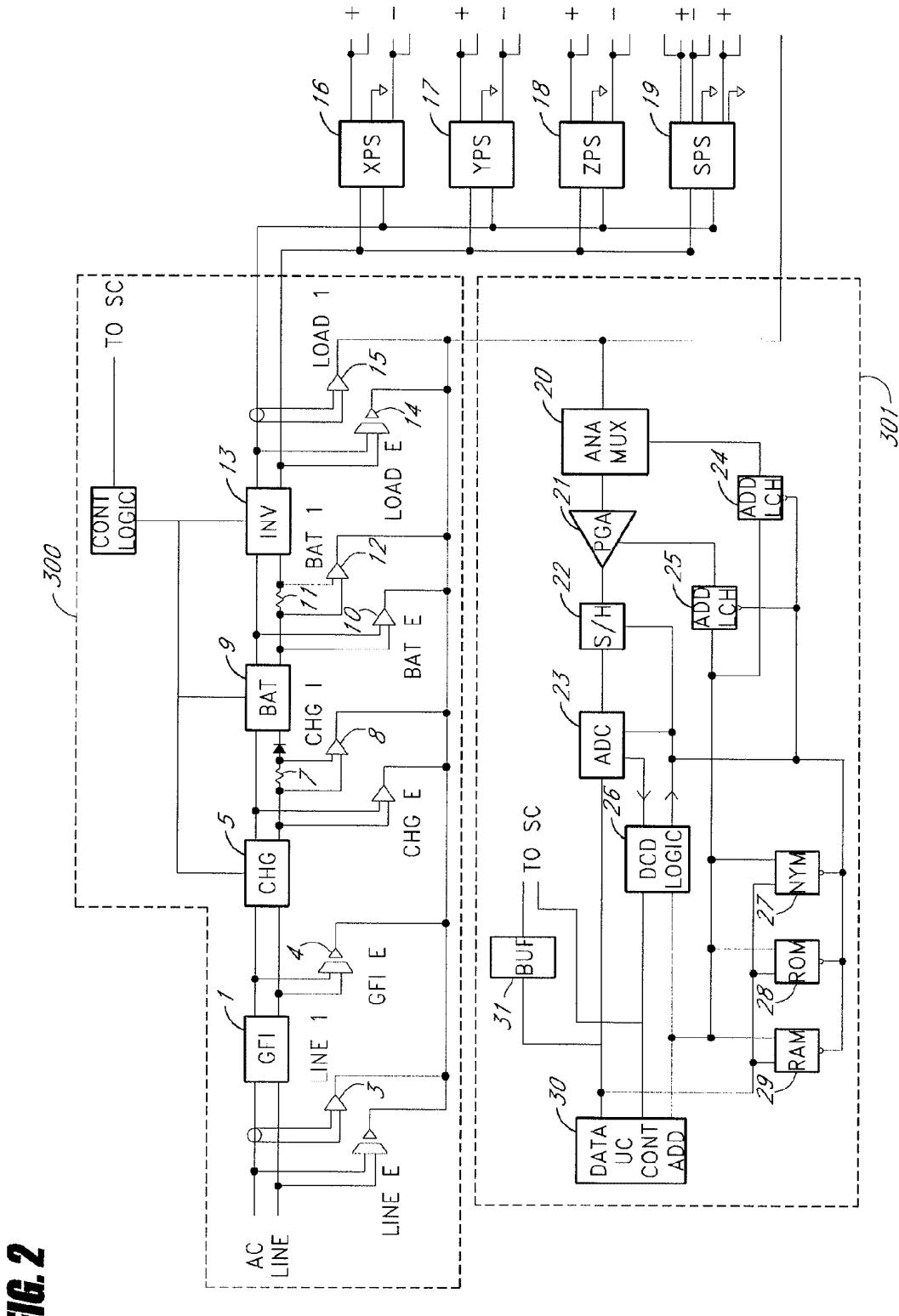
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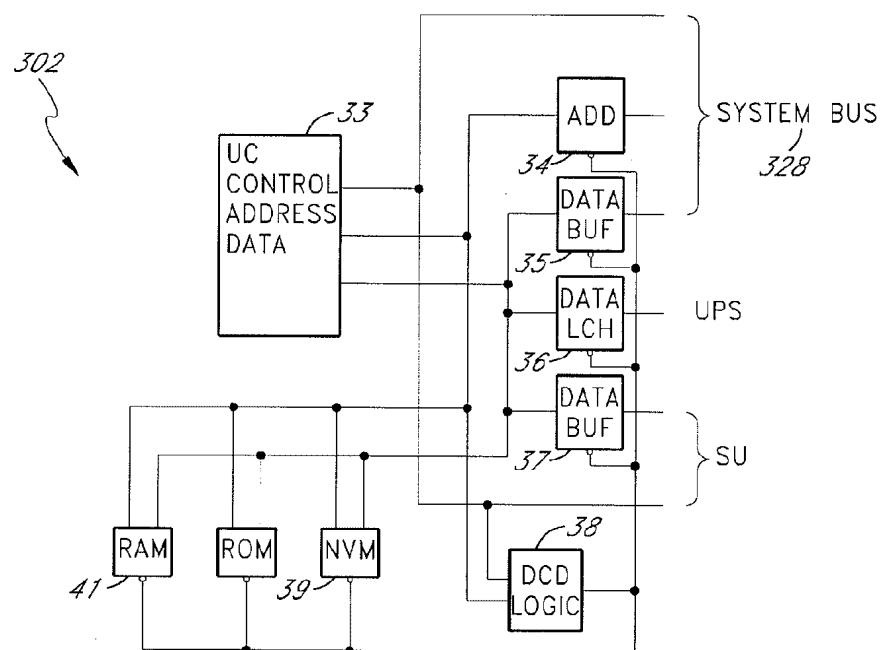


FIG. 3

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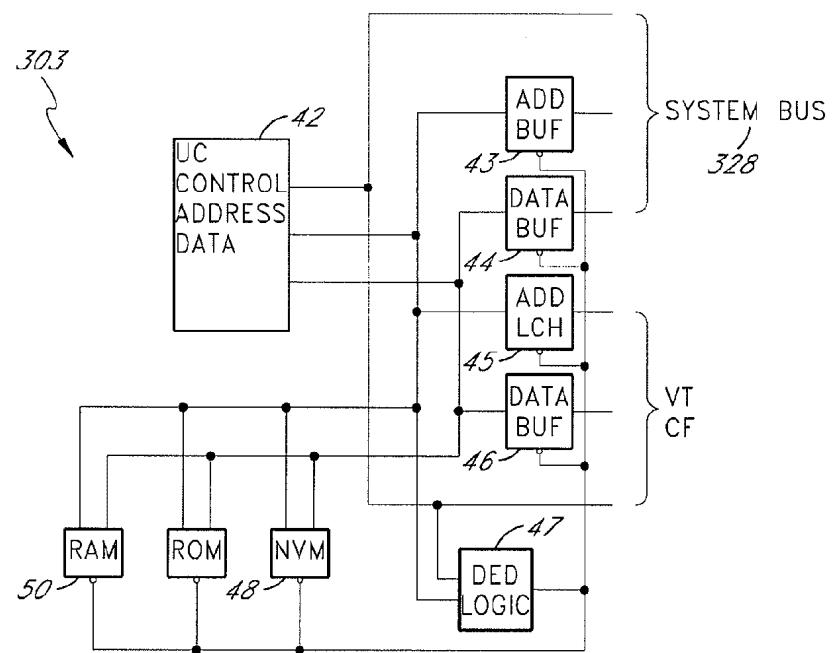


FIG. 4

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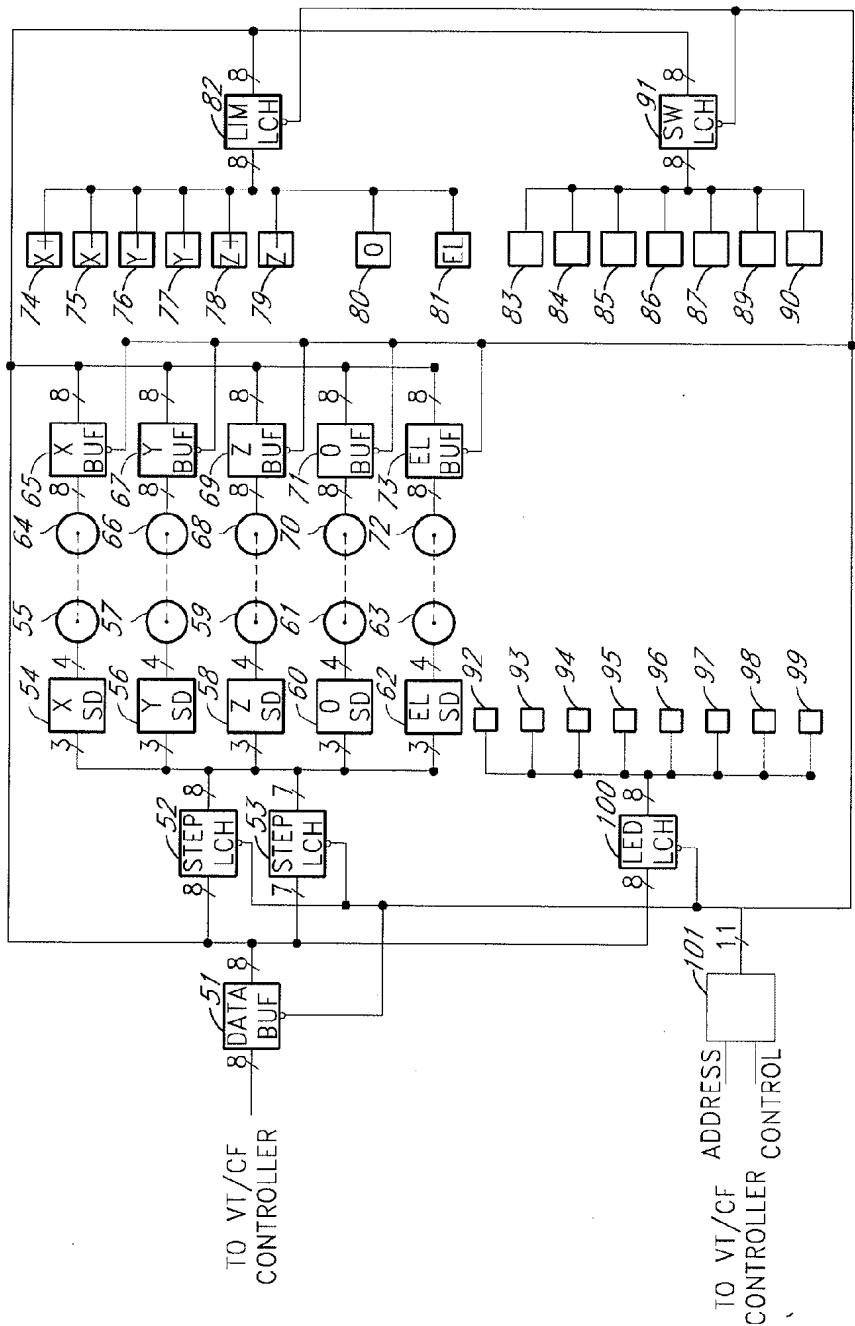


FIG. 5

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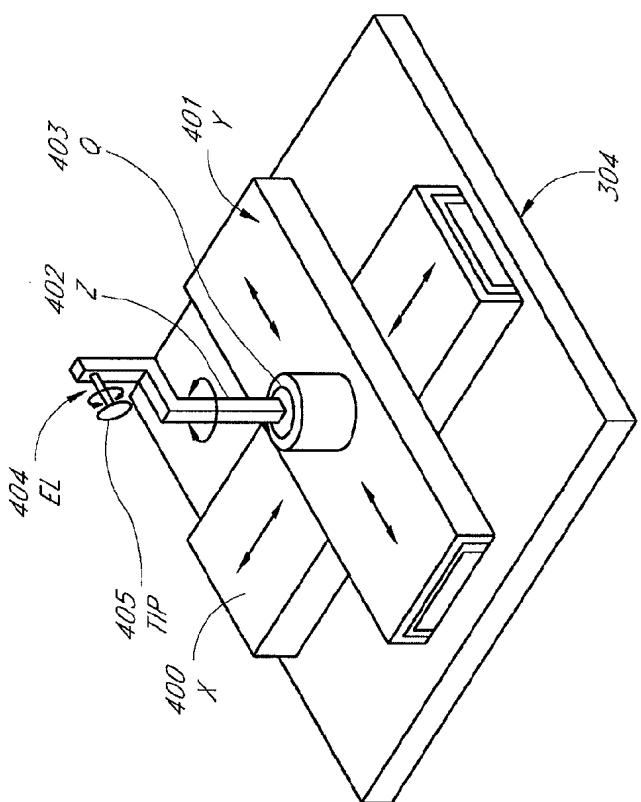


FIG. 6

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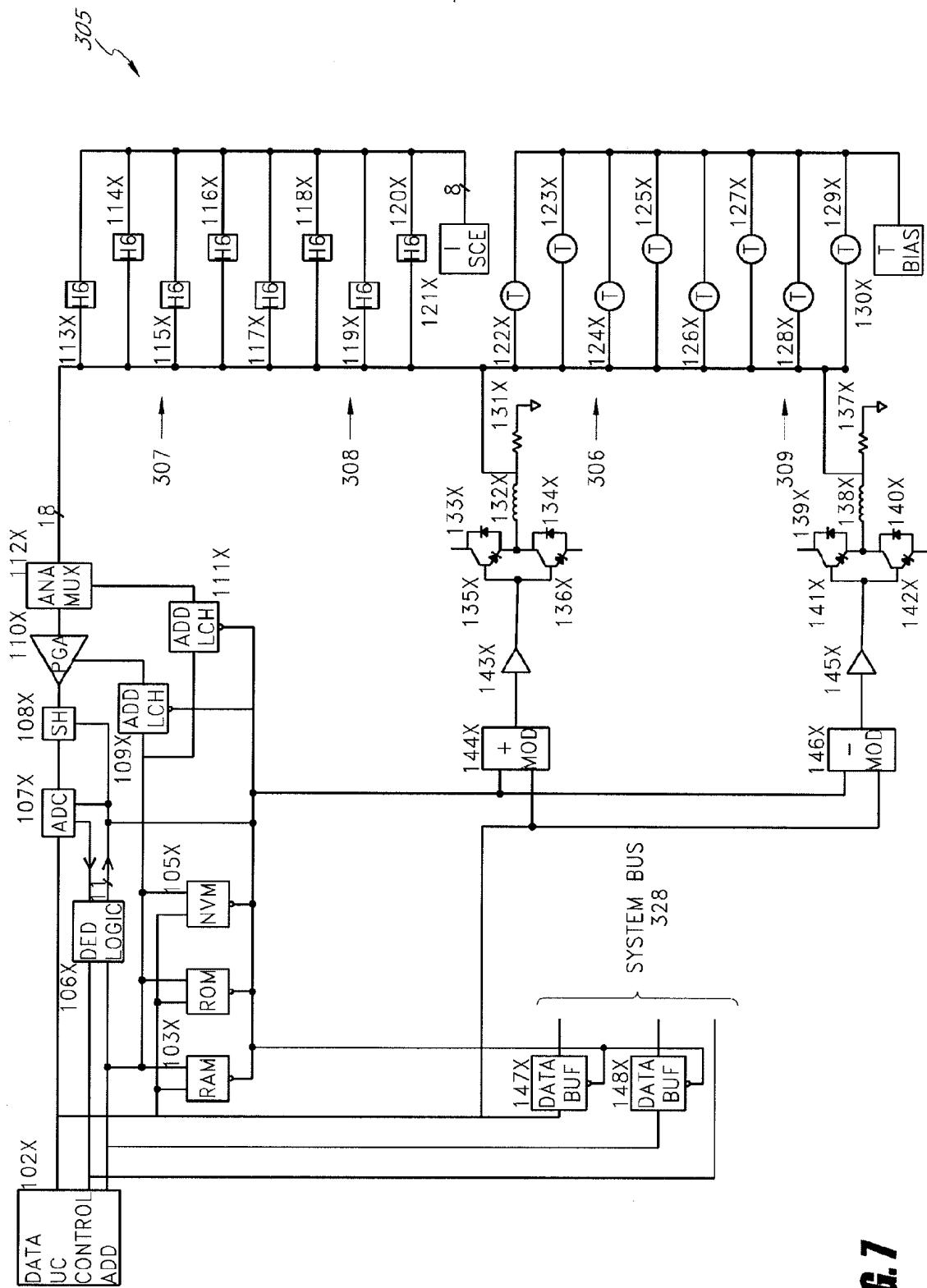


FIG. 7

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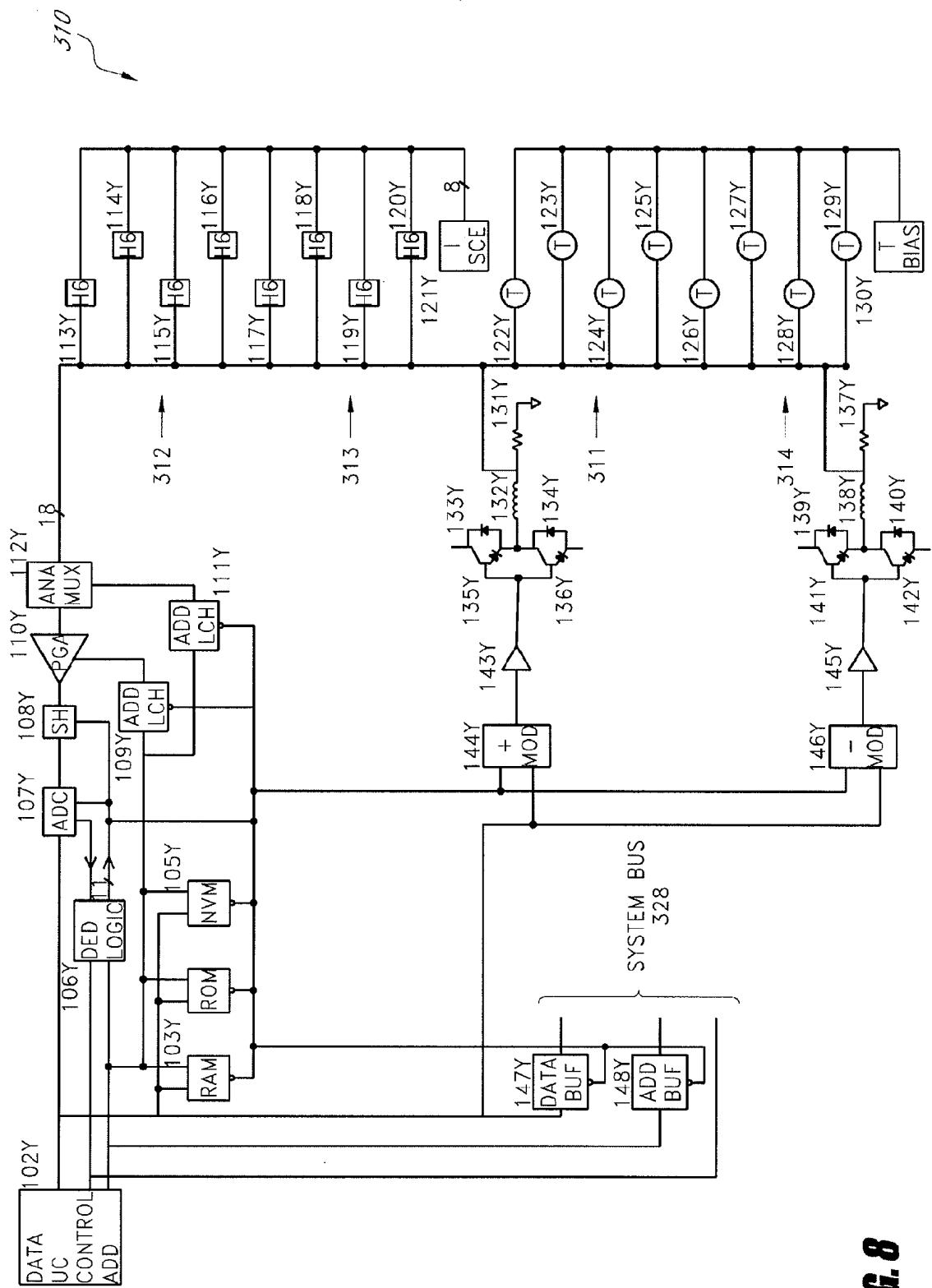


FIG. 8

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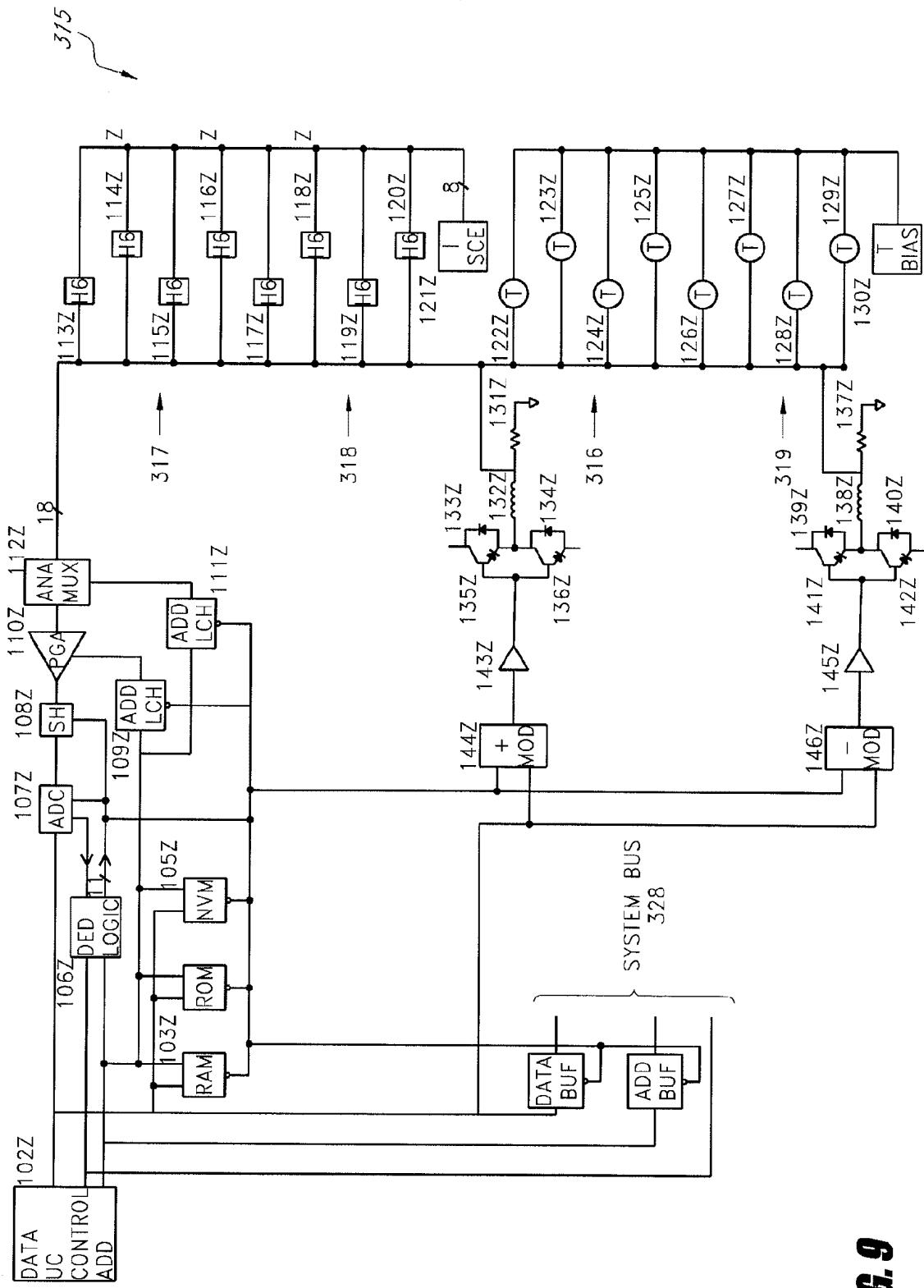


FIG. 9

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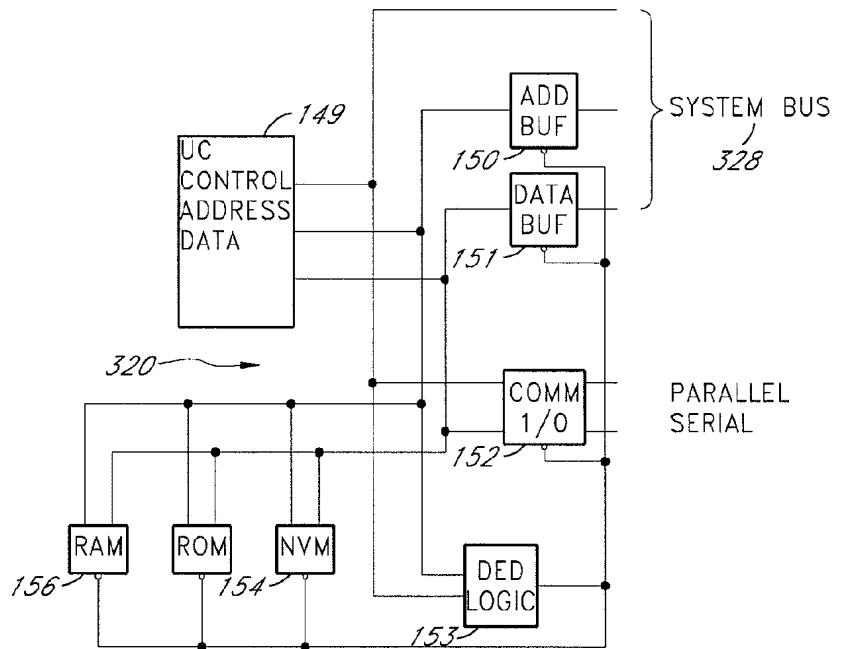


FIG. 10

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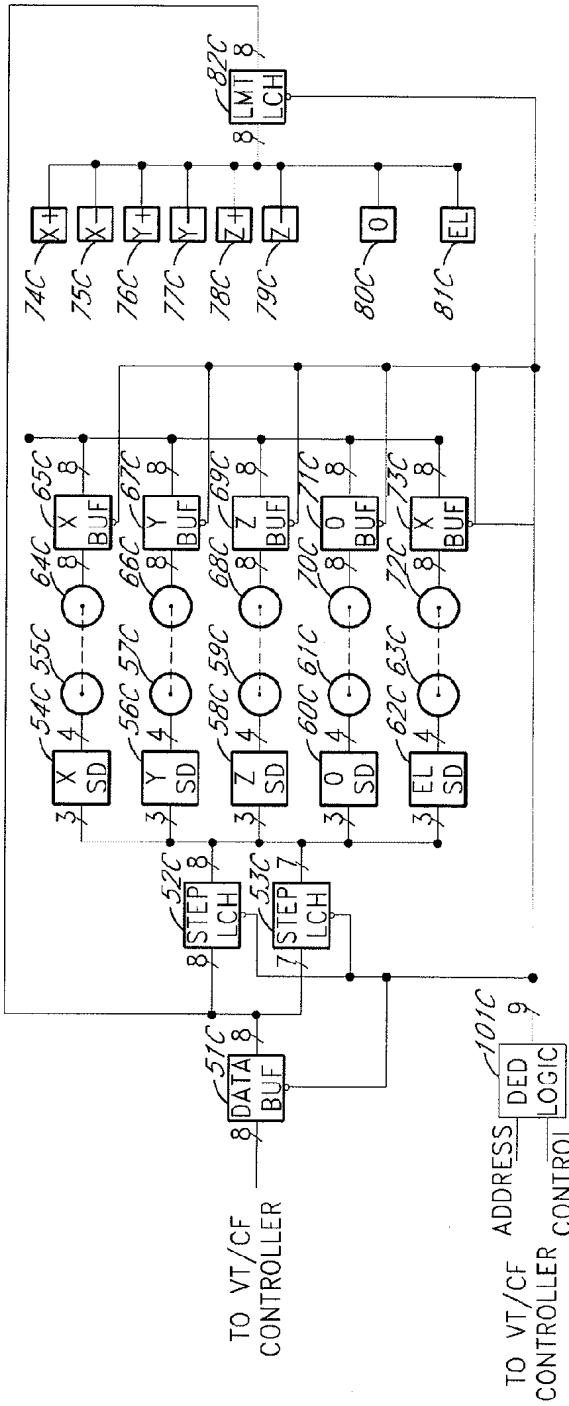


FIG. 11

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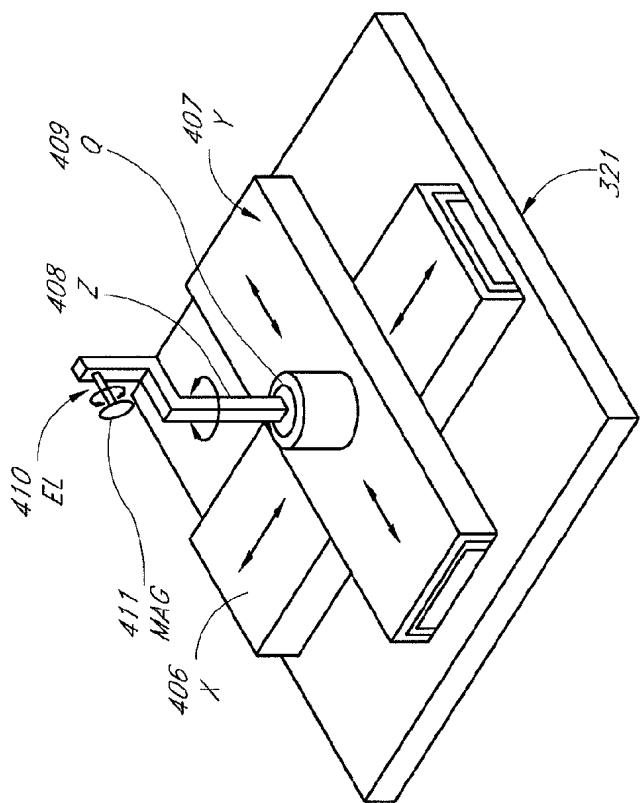


FIG. 12

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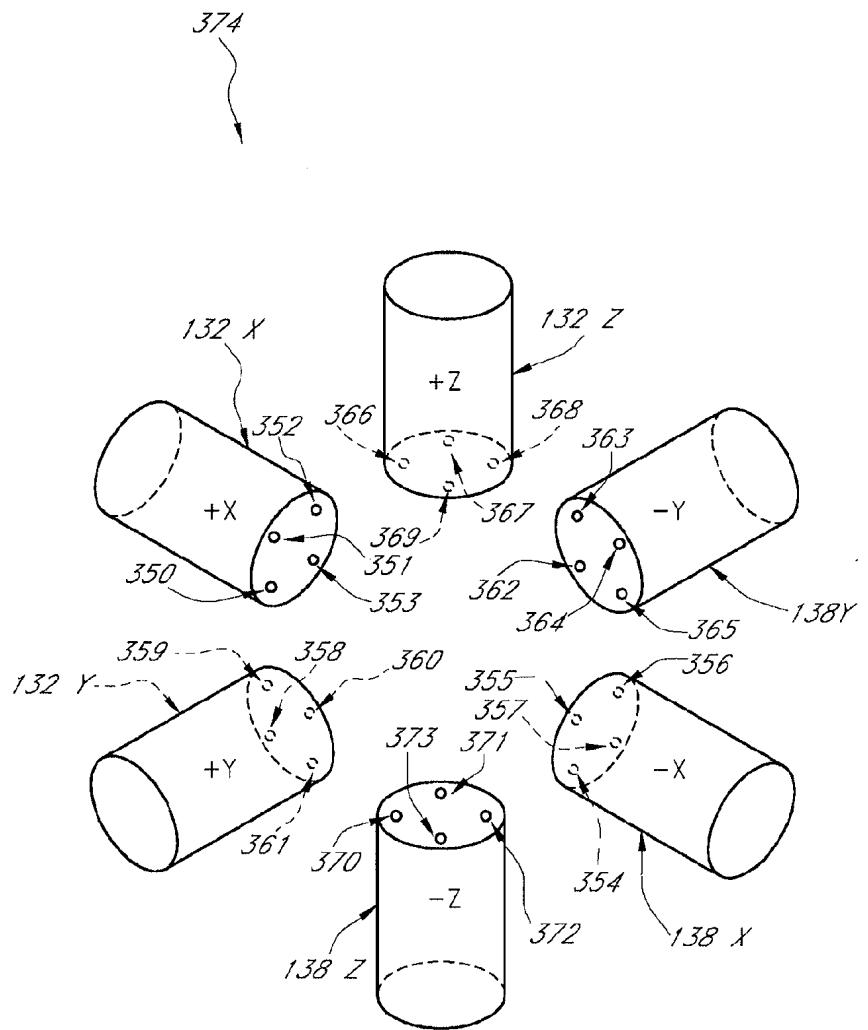


FIG. 13

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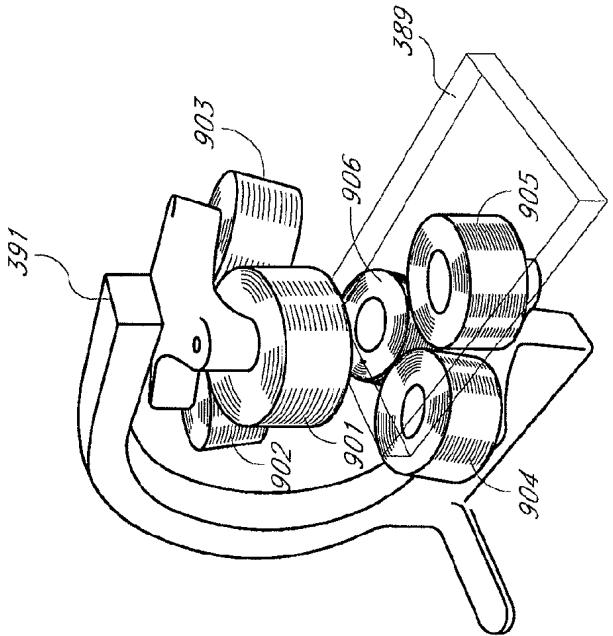
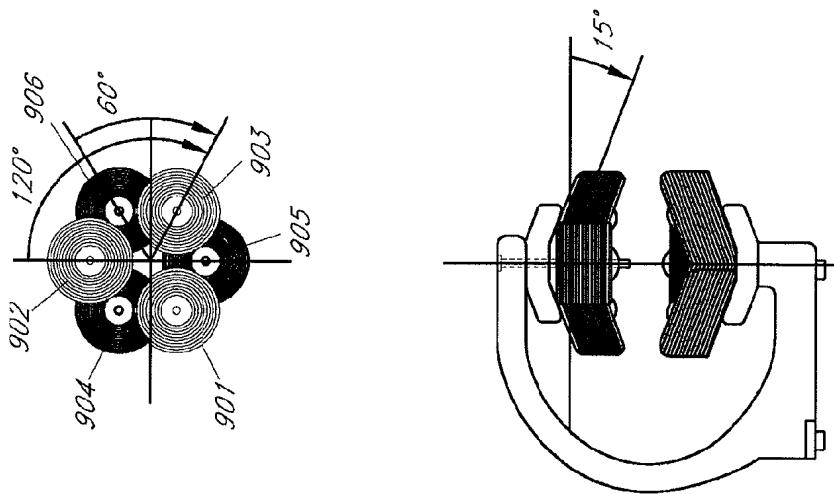


FIG. 13A



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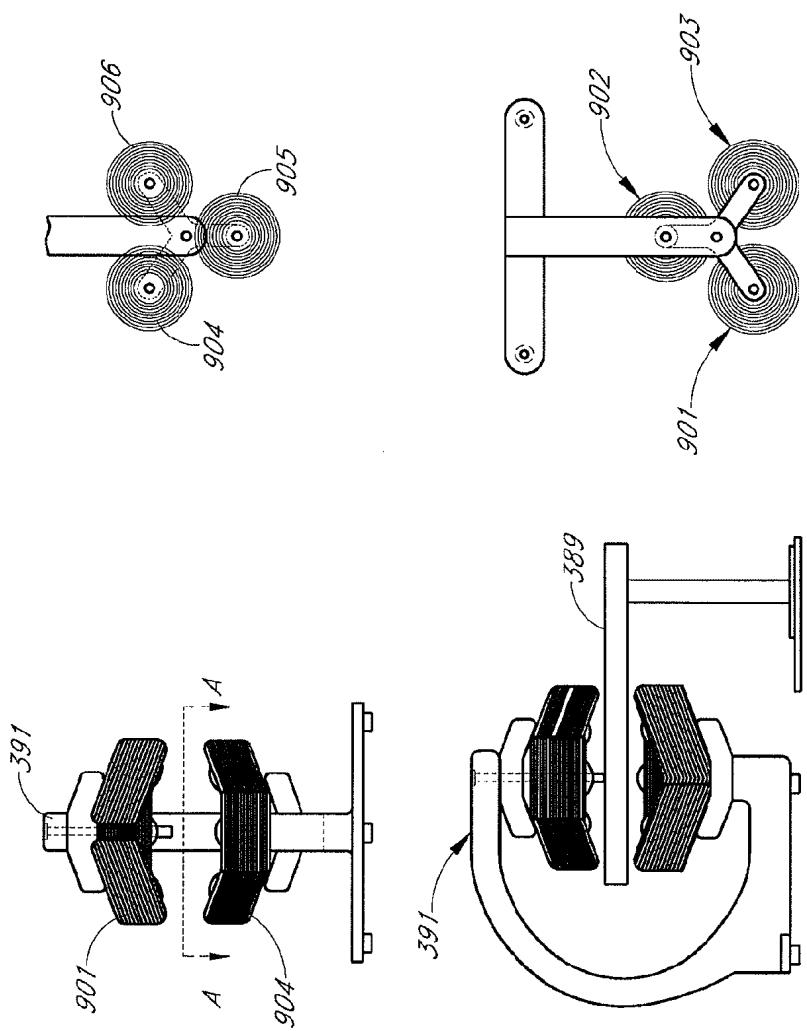


FIG. 13B

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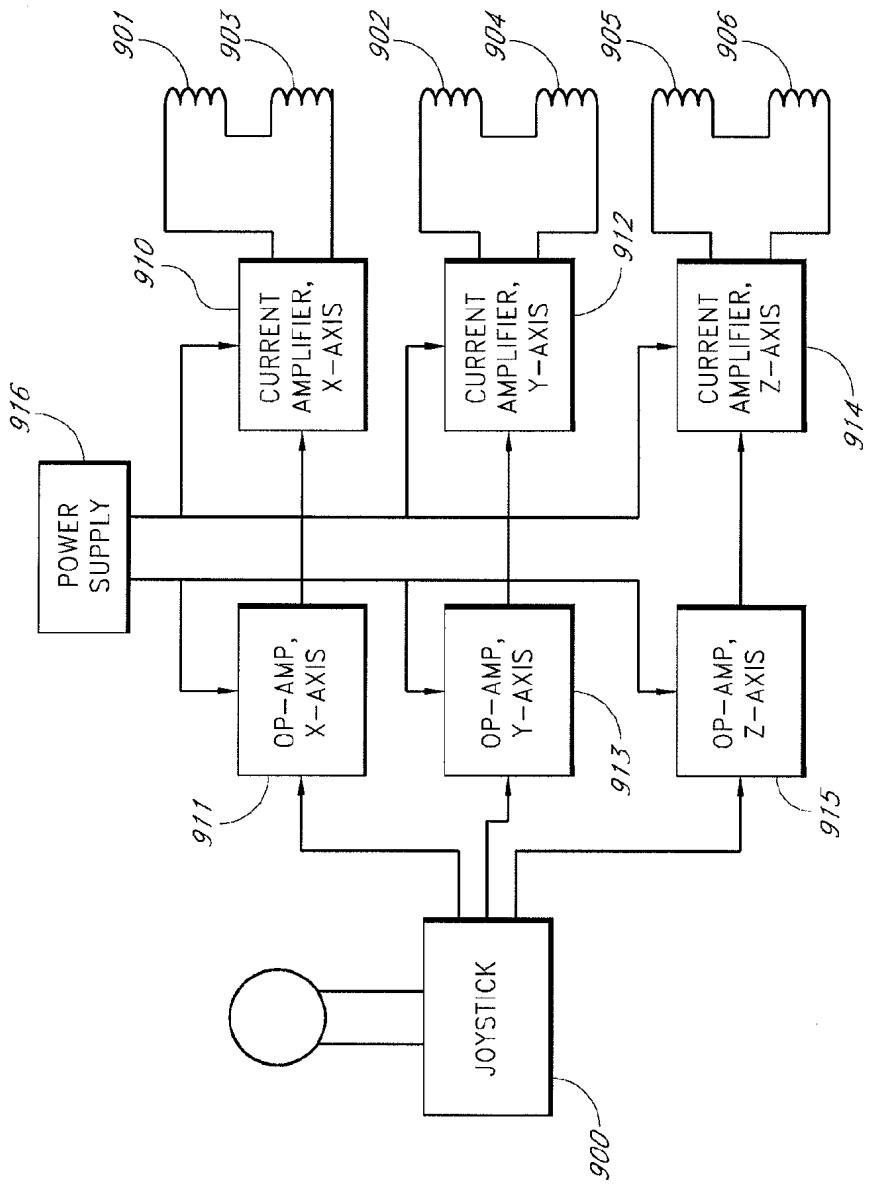


FIG. 13C

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$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} v_{ix} \\ v_{iy} \\ v_{iz} \end{bmatrix}$$

923

FIG. 13D

$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} R_{11}R_{12}R_{13} \\ R_{21}R_{22}R_{23} \\ R_{31}R_{32}R_{33} \end{bmatrix} \begin{bmatrix} l_1 \\ l_2 \\ l_3 \end{bmatrix}$$

927

FIG. 13F

$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} R_{11}R_{12}R_{13} \\ R_{21}R_{22}R_{23} \\ R_{31}R_{32}R_{33} \end{bmatrix} \begin{bmatrix} v_{ix} \\ v_{iy} \\ v_{iz} \end{bmatrix}$$

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FIG. 13G

FIG. 13E

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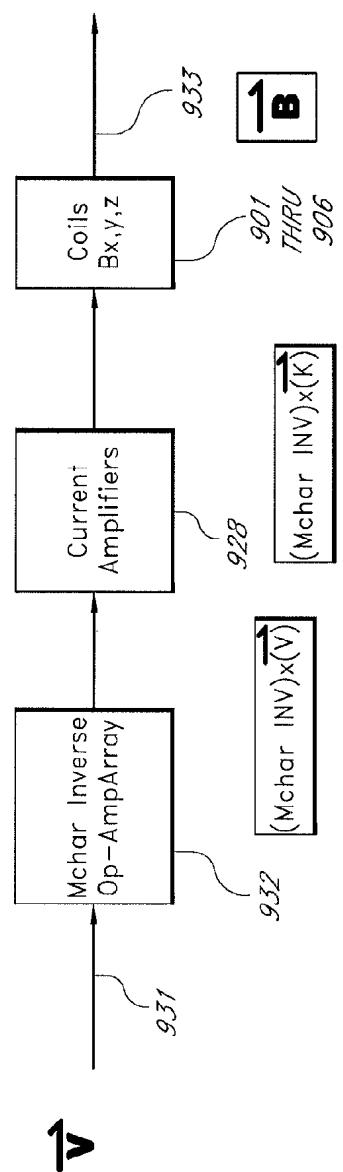


FIG. 13H

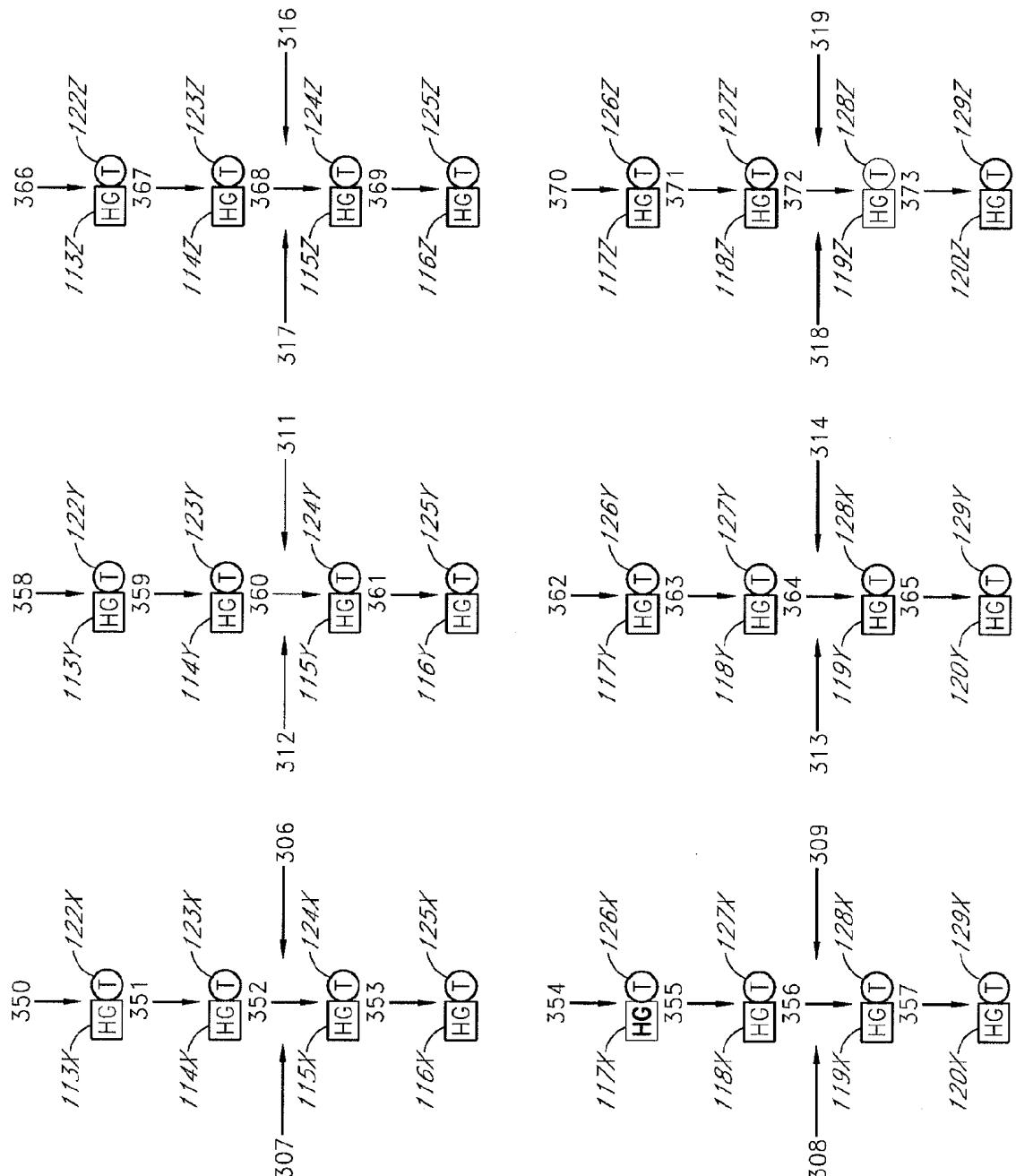
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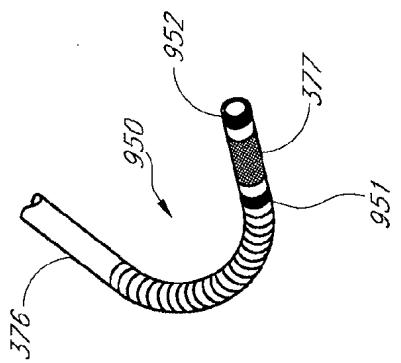


FIG. 15B

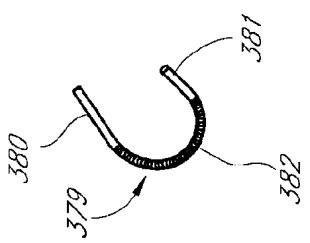


FIG. 15A

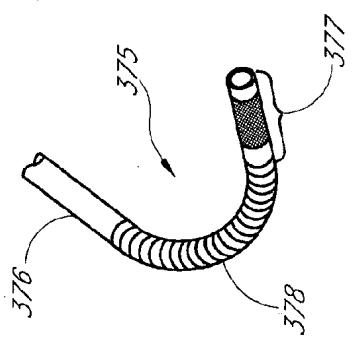


FIG. 15

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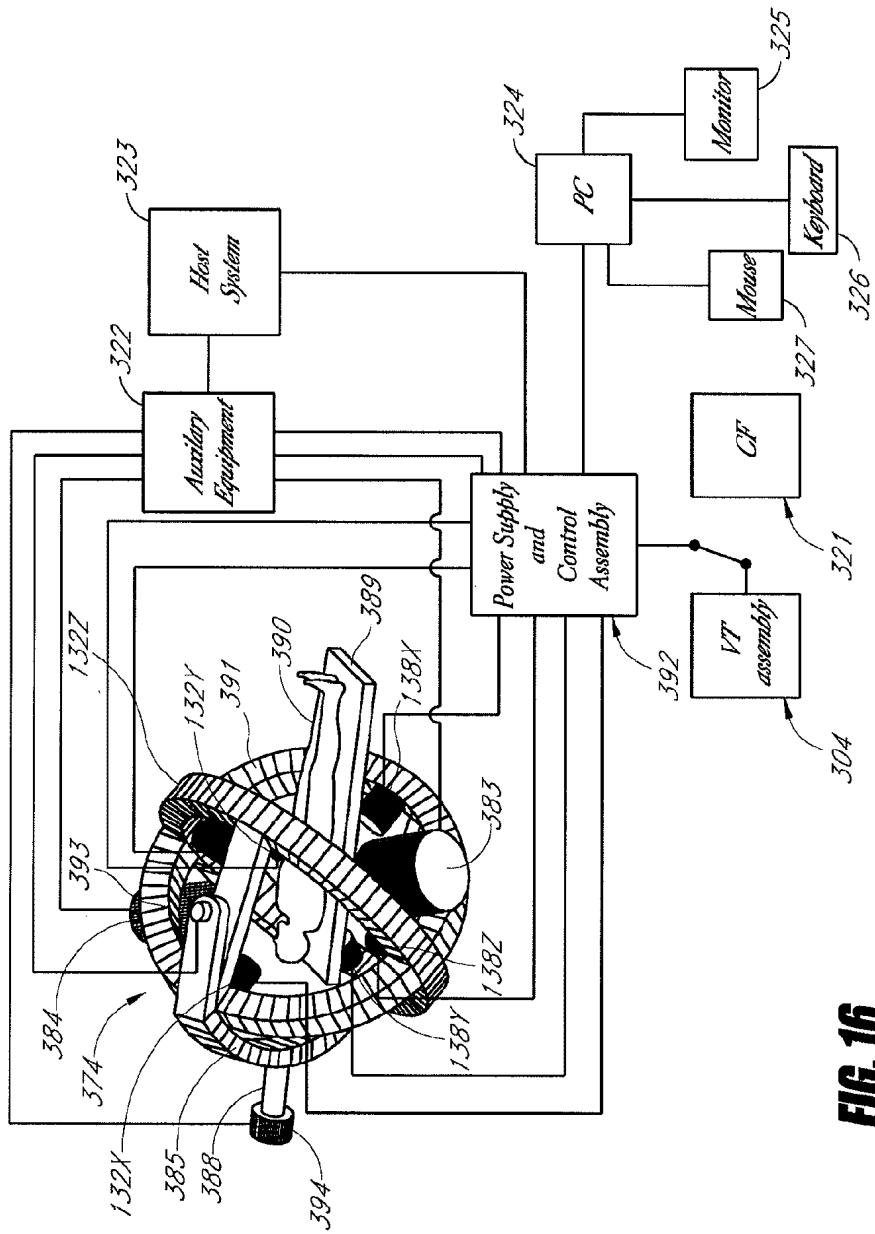


FIG. 16

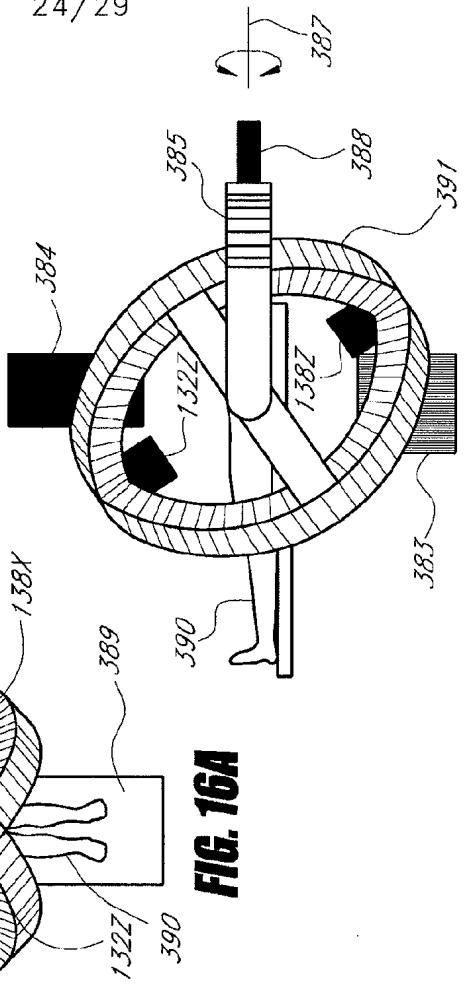
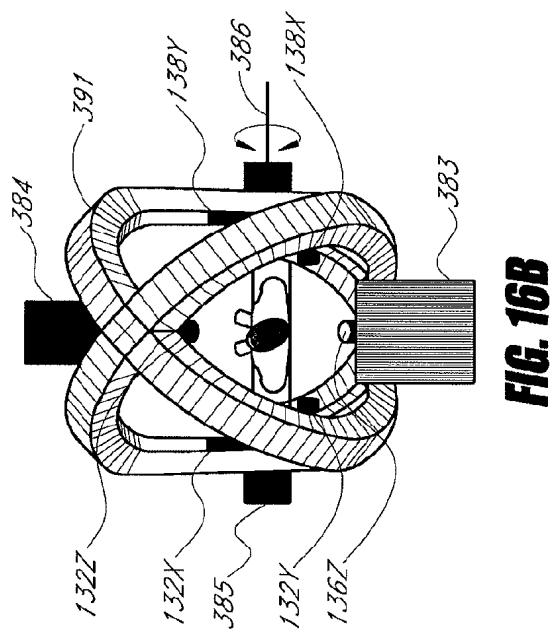
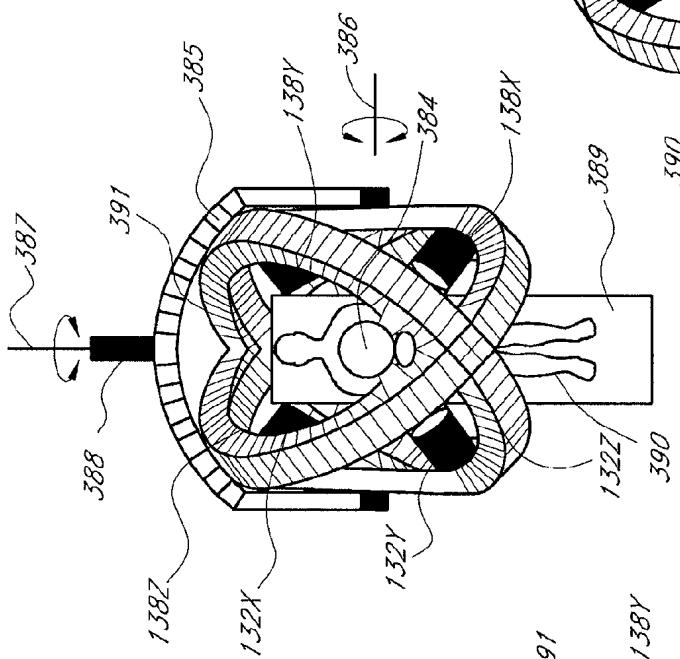
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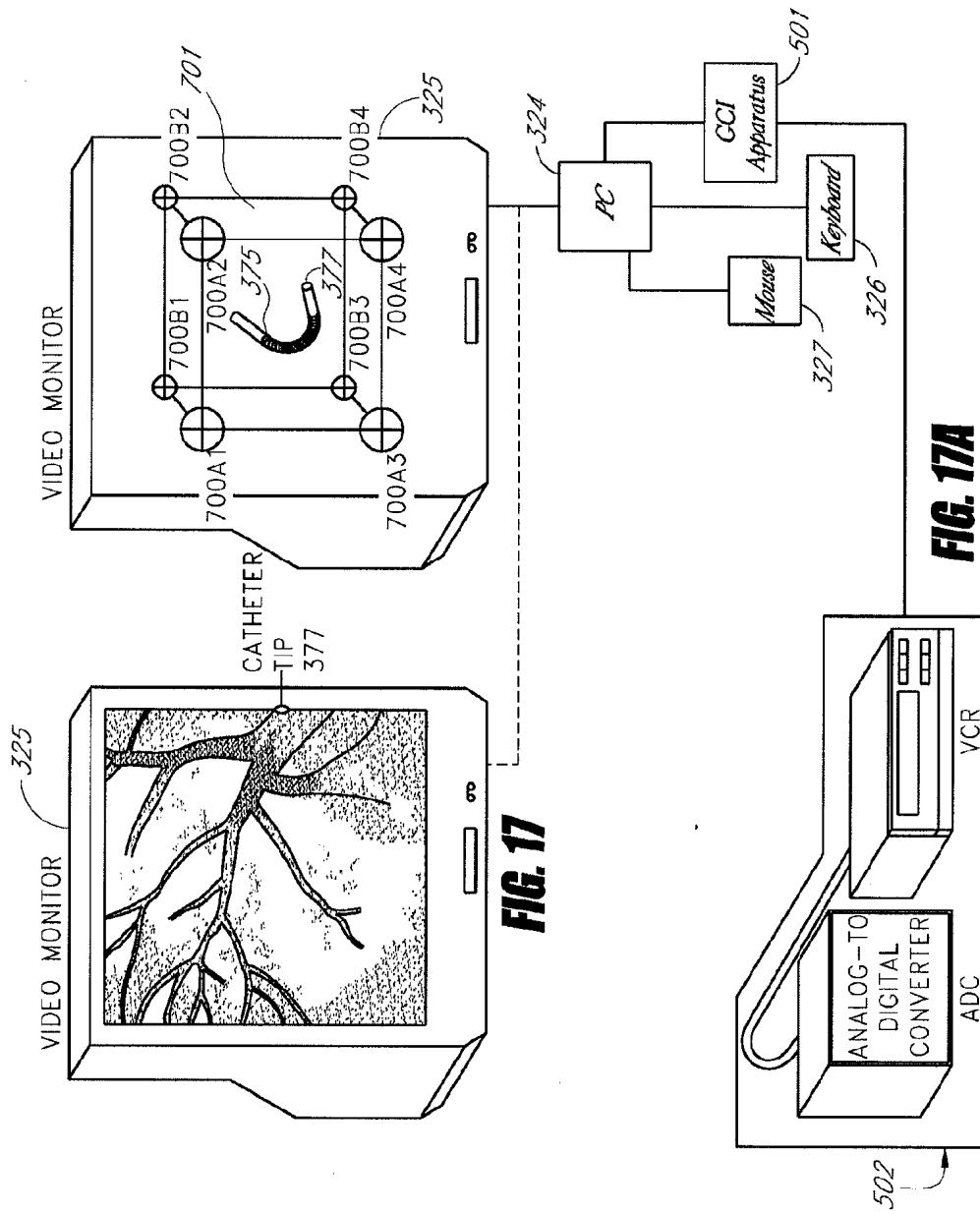
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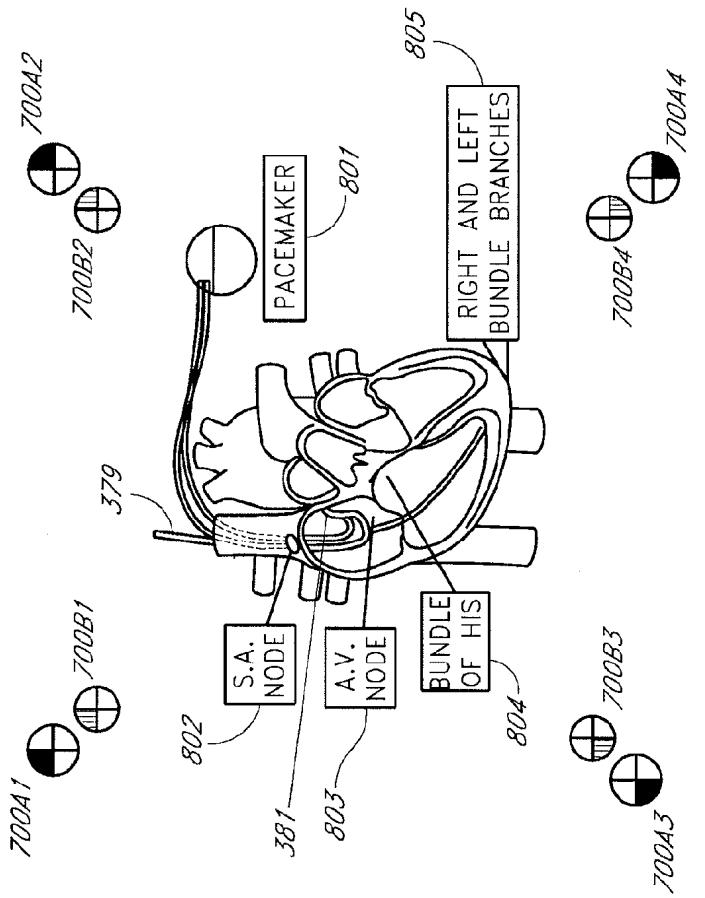


FIG. 17B

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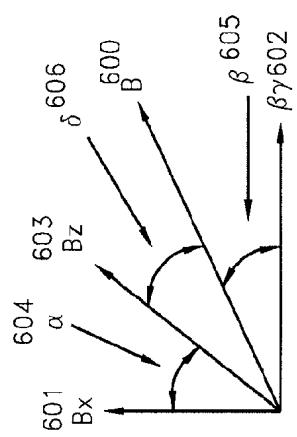


FIG. 18

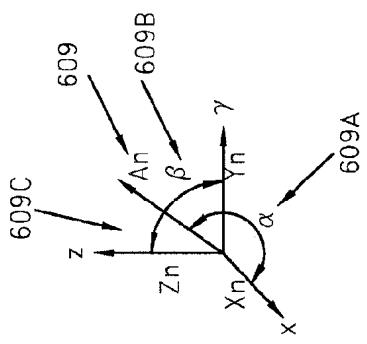


FIG. 18B

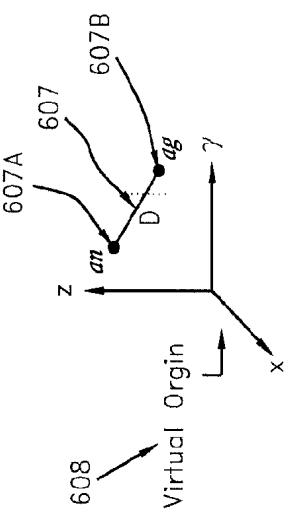


FIG. 18A

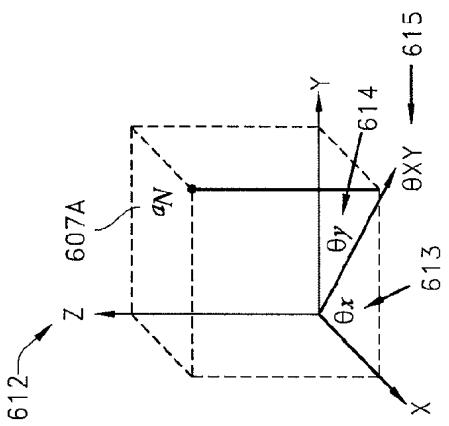


FIG. 18C

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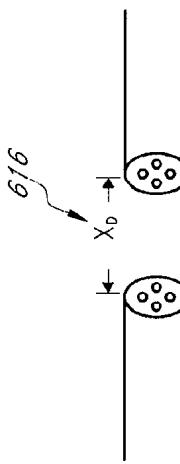


FIG. 19

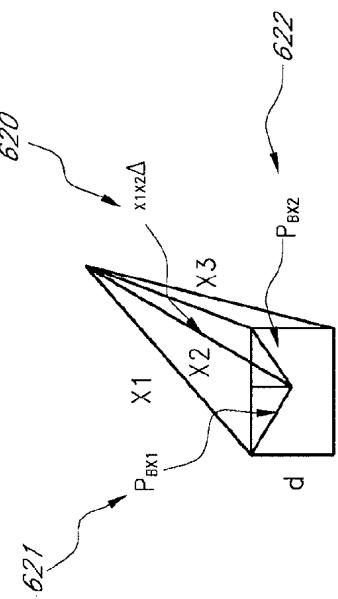


FIG. 20

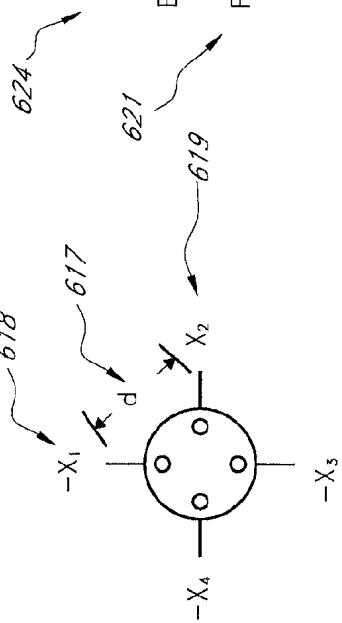


FIG. 19A

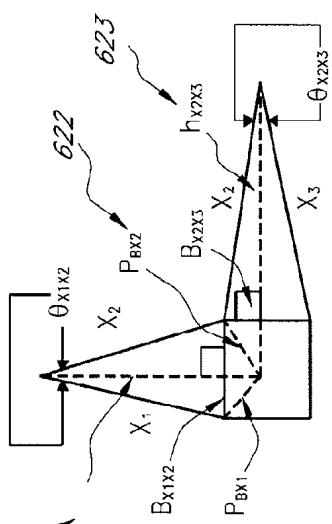


FIG. 204

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